

## Abstract of the Disclosure

A method for programming an industrial robot having a tool. The method includes obtaining configuration data for the tool and for the robot path and information about the position and orientation of the object in relation to the robot, obtaining a sequence of waypoints, which defines the process in relation to the object, obtaining at least one distance for adjusting the position of a waypoint, deciding whether an obtained waypoint should be modified or not, based on the obtained information about the waypoints, generating a modified sequence of waypoints by modifying the waypoints in the obtained sequence of waypoints, based on the decision, the obtained distance and the obtained information about the waypoints and generating the actual robot path based on the modified sequence of waypoints and the obtained configuration data.